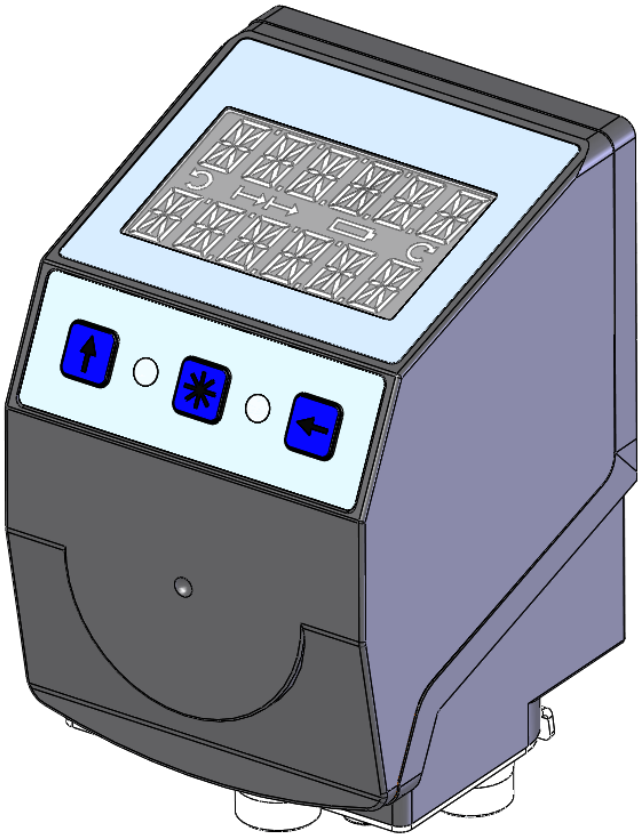
AP10S

Absolute / Electronic Position Indicator with plug connector for magnetic sensor and CANopen interface

User manual



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1 General Information

1.1 Documentation

The following documents describe this product:

- The data sheet describes the technical data, the dimensions, the pin assignments, the accessories and the order key.
- The installation instructions describe the mechanical and electrical installation including all safety-relevant requirements and the associated technical specification.
- The user manual for commissioning and integrating the position indicator into a fieldbus system.
- EDS file (electronic data sheet); this file enables integration and configuration in a CANopen network by means of commercial CANopen configurators.

These documents can also be downloaded at ***http://www.siko-global.com/p/ap10s***.

1.2 Definitions

If not explicitly stated otherwise, decimal values are given as figures without an extension (e. g. 1234), binary values are marked after the figure with an b (e. g. 19011b), hexadecimal values with an h (e. g. 280h).

2 Intended use

The device is an absolute position indicator with a plug-in connection for MS500H magnetic sensor for direct linear distance measurement (combined with MB500 magnetic tape) or a supported GS04 magnetic sensor for direct shaft mounting. Actual and target values are indicated via the backlit two-row LC display. A direction indicator (arrow) is blended in if the actual value deviates from the target value including the adjustable target window. The direction of the arrow indicates the direction of shaft movement necessary to reach the target. Additionally, various visualization tasks can be realized by means of two bi-color LEDs (green and red).

The device parameters can be adjusted by means of 3 keys. You can change the setpoint, output the position value and adjust all device parameters via the integrated bus interface.

Scanning is magnetically-incremental. In the currentless state, scanning and saving of changes of the position value are battery-supported.

The state of charge of the replaceable battery is monitored and signified.

If no sensor is connected or the MS500H sensor lifted off the tape, an error will be detected and the position value displayed red with a flashing "Error" message. This condition survives a power failure. The error must be remedied by way of calibration after checking the sensor connection or sensor position, respectively.

Display and interface are active with external power supply only.

2.1 Switching on the supply voltage

The AP10S will be initialized after switching on the supply voltage. A display test is executed during initialization, the LEDs are lighted consecutively and the configuration parameters are loaded from the non-volatile memory into the RAM of the controller.

With the display still unconfigured all parameters are set to their default values. See to it that the bus will be connected only after correct adjustment of baud rate and ID (see chapter 4.3: Parameterization of the position indicator and chapter 5.6: Auto functions). The AP10S functions with the data last parameterized.
After completing the initialization procedure, the AP10S with CAN interface sends a specific NMT command, the Boot-Up Message, which informs the system about the availability of the display. The AP10S is now in the Pre-Operational Mode. In this state, the display can be parameterized via SDO commands in accordance with the requirements of the application. This applies to configuration parameters as well as to the way it makes available to the system its position values (asynchronous or synchronous data transmission).

3 Display and control keys

3.1 General

The position indicator has a two-line display with special characters and three control keys. The keys serve for position indicator parameterization and control. Two LEDs (1) serve for monitoring positioning.

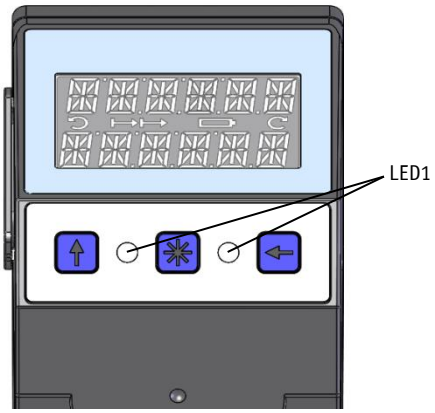

Fig. 1: Control elements

3.2 LCD display

NOTICE	The The display range is limited to -19999 ... 99999. Values outside this range are displayed with "FULL".

With supply voltage applied to the position indicator with factory settings, the actual value will be displayed in the 1st row and the setpoint in the 2nd row. If there is no valid setpoint, "---" will be displayed in the 2nd row. The values displayed are determined by the operating mode.

Direction indicators (arrows) support positioning.

The battery symbol is shown with a critical or insufficient battery status.
With incremental measurement function activated, the incremental measurement symbol is shown.

If battery voltage drops to a critical value, the battery symbol on the display will flash. If it falls below the minimum value, the symbol will glow permanently.

3.2.1 Extended display range

Values up to -999999 can be displayed by means of the control word. If the relevant bit has been set and the value to be displayed is between -199999 and -999999, then the negative sign and the digit of the highest order will flash alternately. If the value range drops below -99999, "FULL" will be displayed.

3.3 LED display

In its basic state (factory setting) the LED display has different meanings depending on the operating mode (see chapter 4.1.1: Position-bound operating modes and 4.1.2: Alpha-numeric display operating mode).
With the basic function of the LEDs inactivated, every LED can be controlled independently via the control word (see object 5F12h: Display orientation and LEDs and chapter 5.3.2: Control word).

3.4 Keys

Pressing the key enables or disables the incremental measurement function. With the Auto-ID function, the new ID is adopted by actuating this key (see chapter 5.6: Auto functions).

Pressing the key starts calibration (see chapter 4.5.1: Warnings) and acknowledges a pending error (see chapter 4.5.2: Errors).

Pressing the key starts the parameterization mode (see chapter 4.3: Parameterization of the position indicator).

4 Functional Description

4.1 Operating modes

The following position-dependent operating modes are differentiated: **Absolute Position**, **Differential Value**, **Modulo** and the position-independent operating mode **Alpha-numeric Display**.

Operating mode	Absolute position	Differential value	Modulo	Alpha-numeric Display
Line 1	Actual position	Actual position	Actual position	Set point1
Line 2	Set point	Differential value	Set point	Set point2

Table 1: Display with different operating modes

Absolute position:

Linear absolute position values are displayed.

Differential value display:

With factory setting: Differential value = actual position - set point

Modulo display:

Position values ranging from 0° to 360° are displayed.

Using the "Decimal places" parameter (see object 5F11h: Decimal places) the resolution and the modulo point of the displayed values are set.

Decimal places	Display resolution	Value range
0	1°	0°...360°
1	1/10°	0.0°...360.0°
2	1/100°	0.00°...360.00°
3	1/1000°	0.000°...360.000°
4	1/10000°	0.0000°...360.0000°

Table 2: Modulo display

Alpha-numeric display:

Both rows can be written freely. Setpoint1 is received via the Receive data object 1 (RPDO1), setpoint2 is received correspondingly with RPDO2. The data identifier must be correctly set in the relevant control word. The data identifier differentiates whether the data is interpreted and displayed as figures or alpha-numeric characters (ASCII) (see chapter 5.3.2: Control word).

4.1.1 Position-bound operating modes

4.1.1.1 Positioning

(see chapter 4.1.1.2: Loop positioning)

Arrows: (see object 5F1Fh: Direction indicators (CW, CCW))

Arrows are displayed to support the user with positioning as long as the current actual position value is outside (see object 5F10h: Target window1 (near field)) target window1. The direction of the arrow indicates the direction of shaft rotation in order to arrive at the setpoint.

LED display: (see e. g. object 5F12h: Display orientation and LEDs)

With factory setting, the LED glows green as long as the actual position is within the programmed window1. When leaving target window1, the LED glows red. The sensor must be adjusted in the direction of the glowing LED in order to arrive at the setpoint. The red glowing LED on the right means: clockwise (cw) rotation required. Red glowing LED on the left: counter-clockwise (ccw) rotation required.

An additional target window (target window2) and an associated visualization can also be configured (5F21h: Target window2 (far) and target window2 visualization).

With factory settings, the LED display has the following meaning:

Operating state	LED	Status	Meaning
There is no valid setpoint.	both	off	Positioning disabled.
There is a valid setpoint.	LED right	off	Target window not reached! The sensor must be moved in positive counting direction in order to reach the target.
		red	Target window not reached! The sensor must be moved in negative counting direction in order to reach the target.
		green	Target window reached
	LED right	off	Target window not reached! The sensor must be moved in negative counting direction in order to reach the target.
		red	Target window not reached! The sensor must be moved in positive counting direction in order to reach the target.
		green	Target window reached

Table 3: LED display

Control word (see chapter 5.3.2: Control word):

The setpoint is not displayed and positioning not monitored unless the setpoint is marked as valid in the control word.

Status word (see chapter 5.3.3: Status word):

Upon reaching target window1, the static and dynamic target-window-reached bits are set in the status word. The dynamic bit is deleted when leaving target window1. The user must acknowledge the static bit.

Example Position monitoring:
Parameterization: Factory setting
Additionally: Set point = 100

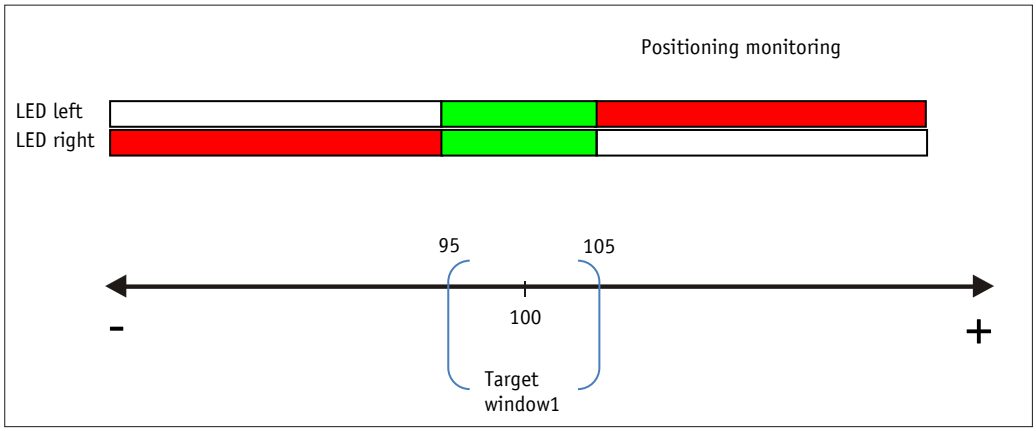

Fig. 2: Positioning monitoring

Example of position monitoring with additionally activated target window2 parameter:

Parameterization:	Factory setting	
Additionally:	Target window 2	= 15
	Visualization target window 2	= 1
	Set point	= 100

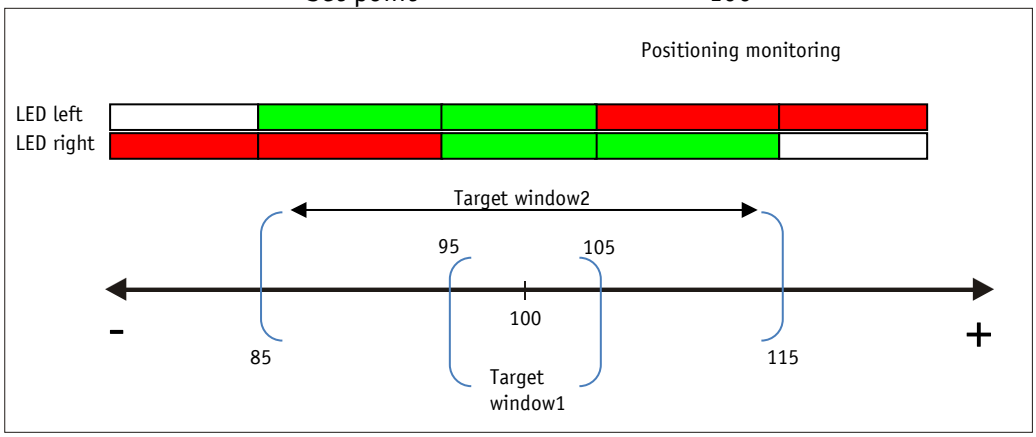

Fig. 3: Positioning monitoring with target window2

4.1.1.2 Loop positioning

NOTICE	Target window1 is also applied to the loop length.

If the position indicator is operated on a spindle or an additional gear, the spindle or external gear backlash can be compensated by means of loop positioning. Therefore, movement towards the setpoint is always in the same direction. This direction of approach can be defined.

Example:

The direction from which every target position shall be driven to is positive.

- Case 1 ⇒ the new position is greater than actual position:

Direct travel to the target position.

- Case 2 ⇒ the new position is smaller than actual position:

The position indicator's arrows show that the set point is to be overrun by the loop length. Afterwards, the set point is approached in positive direction.

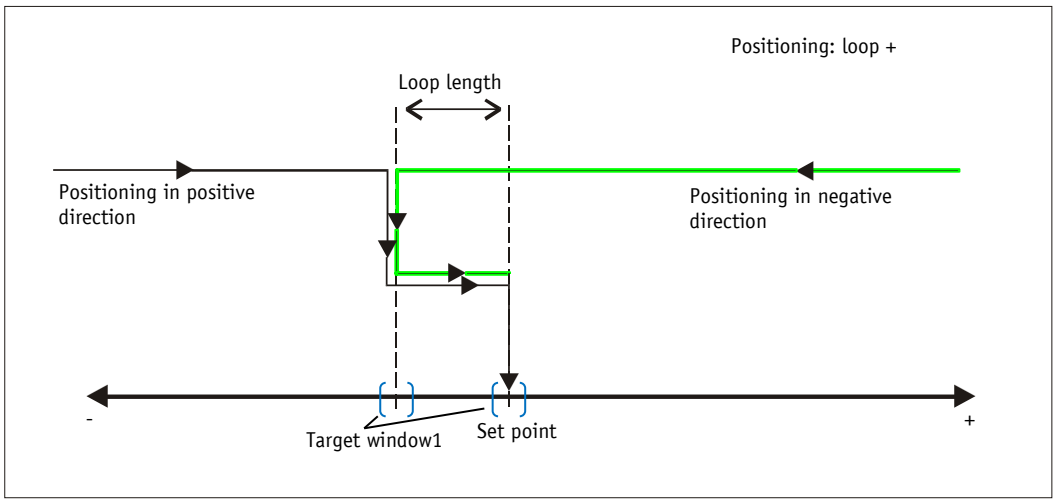

Fig. 4: Positioning Loop+

4.1.2 Alpha-numeric display operating mode

Two 6-digit setpoints can be displayed in this operating mode. With factory settings, the setpoints are acknowledged by pressing the asterisk key (see chapter 3.4: Keys).

LCD display:

In the absence of a valid setpoint, the 1st row is displayed empty (blank). " --- " appears in the 2nd row.
A valid setpoint flashes until it is acknowledged.

LED display:

With factory settings, the LED display works according to the following table.

Operating state	LED	Status	Meaning
There is no valid setpoint.	both	off	
There is a valid setpoint.	LED left	red	Setpoint1 not acknowledged
		green	Setpoint1 acknowledged
	LED right	red	Setpoint2 not acknowledged
		green	Setpoint2 acknowledged

Table 4: LED display in the alpha-numeric display operating mode

Control word:

In the control word, the relevant type (number or character string) and the validity of the setpoint is transmitted to the display. As an additional option, the setpoint can be acknowledged via the control word.

Status word:

Type, validity and acknowledgement status of the setpoints are fed back in the status word.

4.2 Battery buffering

The battery makes possible the detection of currentless displacement. Battery life is approx. 5 years depending on the duration of battery operation (including storage) and frequency of currentless adjustments. Battery voltage is checked at intervals of approx. 5 min. If battery voltage drops below a specified value, the battery symbol will blink on the display. If the battery voltage continues to drop, will be displayed permanently. The battery should be replaced within approx. three months after the first appearance of the battery symbol. The battery can be replaced by the SIKO distribution partners or at the SIKO main factory. For battery replacement it is mandatory to follow the instructions of the installation instructions.

Status word:

The charge status of the battery is signified in the status word. CANopen Emergency messages are sent upon detection of a critical charge state and with detection of the empty state (see chapter 5.5.1: Emergency Service (EMCY)).

4.3 Parameterization of the position indicator

The position indicator can be fully parameterized via the bus interface. You can configure manually via keyboard the most significant bus parameters (node address and baud rate).

4.3.1 Manual parameterization

4.3.1.1 Starting parameterization

After applying supply voltage and completion of initialization, the position indicator is on the uppermost level of the menu structure (default / Factory settings).
By actuating the ← key, the set node address and baud rate is displayed. Parameterization starts if it is actuated for the duration of the enable time (see object 2005h: Configuration enable via keyboard and delay of start of configuration).

4.3.1.2 Value input

Enter values via the ↑ key and the ← key. Confirm values entered by pressing the ✱ key.

← - decimal place selection key

↑ - value input key

4.3.1.3 Value selection

For some parameters you can select values from a list.

Direct value input is not possible there.

Pressing the ↑ key, the value can be selected from the list. By pressing the ✱ key, the selection is confirmed.

4.3.1.4 Adjustable parameters

The following parameters can be adjusted.

Display	Parameter	Options
ID	Node-ID	1 ... 127 (see chapter 5.6.2)
KBAUD	Baud rate	Auto baud (see chapter 5.6.1)
		125 kbaud
		250 kbaud
		500 kbaud
		800 kbaud
		1000 kbaud
CODE	System commands	Load factory settings (see chapter 4.6.3)
		Start diagnosis (see chapter 4.6.4)

Table 5: Manually adjustable parameters

4.3.2 Parameterization via interface

The position indicator can be completely parameterized in the CANopen interface (see chapter 5.4: Parameter data exchange).

4.4 Sensor

Mounting of the sensors as well as installation of the sensor cable is explained in the documentation pertaining to the sensor MS500H or GS04. With 24 V supply voltage operation the display controls the connected sensor. If no sensor is connected or if the sensor is lifted from the tape (MS500H), an error will be detected and the position value displayed red with flashing "Error". This status persists even with power supply failure. The error must be corrected after checking the sensor connection or sensor position with calibration (see chapter 3.4: Keys and chapter 4.6.2: Calibration). If both battery supply and power supply fail simultaneously (e. g. during a battery change), the absolute position value can get lost. For making the measuring system work again, calibration is required (see chapter 4.5.2: Errors and 4.6.2: Calibration). Alignment travel is required if a new sensor is connected (see chapter 4.6.1: Calibration travel).

4.5 Warnings / Errors

4.5.1 Warnings

Warnings do not influence the acquisition of the absolute position value.
Warnings are deleted after removing the cause.

Possible warnings:

- Battery voltage for absolute position detection is below limit ⇒ immediately exchange battery!
  This warning is displayed with a blinking battery symbol ▭. Via status word and the emergency service, warning messages are output via the interface (see chapter 5.3.3: Status word, chapter 5.5.1: Emergency Service (EMCY) and chapter 5.5.1: Emergency Service (EMCY)).

Display	Error code Emergency	Bit assignment in the status word	Error
▭ blinking	3200h	11	Low battery voltage

4.5.2 Errors

Error states are signalled via display and interface.
To return to normal operation, the cause must be removed (see Table 7: Corrective actions) and the fault message acknowledged or deleted via ✳ key.

(For signaling see chapter 5.3.3: Status word, chapter 5.5.1: Emergency Service (EMCY) chapter 4.6.4: Diagnosis)

Display	Error code Emergency	Bit assignment in the status word	Error
▭ permanent	3200h	11+7	Low battery voltage (empty)
SENBND	FF10h	12	Tape-sensor gap exceeded
noSENS	FF11h	12	No sensor connected
SPEED	FF12h	12	Travel speed exceeded

Table 6: Error messages

Display	Error	Possible effect	Corrective actions
▭ permanent	Battery empty	Position value not reliable	Battery change + calibration travel
SENBND	Tape-sensor gap exceeded	Position value not reliable	Check sensor position + calibration travel
noSENS	No sensor connected	Position value not reliable	Check sensor + calibration travel
SPEED	Admissible travel speed exceeded (see installation instruction) Error may also occur during alignment travel.	Position value not reliable	Decelerate travel speed + calibration travel

Table 7: Corrective actions

4.6 System commands

4.6.1 Calibration travel

The AP10S is fully functional as delivered. To adjust the display to the connected sensor and to achieve optimum measuring accuracy, calibration travel must be carried out whenever a new/different sensor is connected to the AP10S. For calibration, the sensor must have been mounted correctly (see documentation MS500H or GS04).

1. By entering CODE 000100, AP10S is set to the alignment mode (see chapter 4.3.1: Manual parameterization).
   Display: 1st line. "ADJUST"
   2nd line. "100" this value may vary by ±1.
2. When connecting sensor MS500H, it must be moved by a few millimeters in the direction of the cable outlet (speed <1 cm/s).
   When connecting sensor GS04, the shaft must be rotated clockwise by a few millimeters (speed <<1 U/min).
   In the lower line, the value will change in positive direction up to "103".
3. The alignment process will be completed when this value is finally exceeded. AP10S has returned to normal operation and shows the corresponding display. If values above 103 are displayed during alignment, then travel speed must be slowed down during alignment.
4. It is not unusual that the position value cannot be displayed immediately after alignment travel and "FULL" is displayed instead of the value. The display should be calibrated in this case (see chapter 4.6.2: Calibration).

4.6.2 Calibration

Two steps are required for executing calibration:

1. Write calibration value (see object 6003h: Preset value (calibration value))
2. Execute calibration (reset) (see chapter 3.4: Keys or object 2002h: Calibrate encoder value)

Since the measuring system is an absolute system, calibration is necessary only once with commissioning. With calibration, the calibration value is adopted for calculation of the position value. The following equation is applied in case of calibration:

Position value = 0 + calibration value + offset value

Calibration value (see object 6003h: Preset value (calibration value))

Offset value (see object 2001h: Manufacturer Offset)

4.6.3 Restore factory settings

There are various options for restoring the factory settings of the device:

Access	Coding		Factory settings are restored
Manuell	CODE	011100	all parameters
		011102	all except bus parameters
		011105	only bus parameters
CANopen (see object 1011h: Restore Parameter)	1011h "load"	Subindex 1	all parameters
		Subindex 2	only bus parameters
		Subindex 3	only Draft-Standard-406 parameters
		Subindex 4	only manufacturer-specific parameters

Table 8: Access to factory settings

4.6.4 Diagnosis

To receive a list of all errors occurring from chapter 4.5.2 of the device, the device must be switched to diagnosis operation. Enter CODE "200000" in parameterization (see chapter 4.3.1: Manual parameterization) and confirm by pressing the ✳ key. Any errors occurring are output indicating the error number and total of occurrences in the upper row. The type of error is shown in the lower row. Error number 1 contains the latest error. The oldest error is output with the highest error number.

5 Communication via CAN bus (CANopen)

The CiA DS-301 V4.2 CANopen communication profile as well as the Device profile for Encoders CiA DS-406 V3.2 form the basis for AP10S, which supports device class C2. As this device is beyond the scope of an encoder's functionality, communication partly differs from the above-mentioned device profile. This document contains the details necessary for understanding the operation of the device. If more-in-depth information is required we recommend to consult the pertinent specialized literature on CAN or CANopen.

5.1 Telegram setup

The data telegram of a CAN message consists of the following fields:

SOF	Identifier (COB-ID)	Control field	Data field (max. 8 byte)	CRC	ACK / EOF

SOF:

(Start of Frame) start bit of the telegram

Identifier (COB-ID):

- All bus sharing units check via identifier whether the message is relevant for them.
- The identifier sets the priority of the message. The lower the value of the identifier, the higher the priority of the message. This results in preferential transfer of messages via the bus.

The Identifier field contains the identifier as well as bits for the recognition of the length of the identifierss (11 or 29 bit). Furthermore, the identifier serves for determining the device address, the channel selection as well as the direction of data transfer.

The 11bit identifier (COB identifier) consists of a 4bit function code and a 7bit node number:

Bit no.	10	9	8	7	6	5	4	3	2	1	0
Type	Function code				Node number (node ID)						
Assignment	x	x	x	x	0	0	x	x	x	x	x

The following function codes have been defined in the "Pre-defined Connection Set" (only the function codes used in the present device are listed):

Object	Function code	Resulting COB-ID	Object	Page
Network management (NMT)	0000b	0	-	20
SYNC message	0001b	128 (80h)	1005h	38
Emergency message	0001b	128 (80h) + Node-ID	1014h	44
TPD01	0011b	384 (180h) + Node-ID	1800h	51
RPD01	0100b	512 (200h) + Node-ID	1400h	47
TPD02	0101b	640 (280h) + Node-ID	1801h	53
RPD02	0110b	768 (300h) + Node-ID	1401h	48
SDO (tx)	1011b	1408 (580h) + Node-ID	1200h	46
SDO (rx)	1100b	1536 (600h) + Node-ID	1200h	46
Heartbeat message	1110b	1792 (700h) + Node-ID	-	29
Node Guard message	1110b	1792 (700h) + Node-ID	-	28

Table 9: Overview of COB identifiers

Changes to COB-IDs are only possible in the PRE-OPERATIONAL NMT status. First, the COB-ID must be deactivated via Bit 31 = 1b before it can be changed and reactivated.
The COB-ID of the SYNC object is an exception. There, Bit 30 must be = 0 to enable the change of the COB-ID. The COB-ID could be changed any time because Bit 30 cannot be set to 1 in the AP10S device.
The identifier determines the priority of the message. The lower the value of the identifier, the higher the priority of the message.

The node number (Node-ID) (see object 5F0Ah: Node-ID, Auto-ID and Baud rate Bus CAN) is assigned in every bus system once while AP10S is being configured. Node-ID = 0 is reserved and must not be used; thus the node numbers are in the range of 1 to 127.

A newly set node number will only be adopted with reinitialization (see chapter 5.2.1: Network management services (NMT)).

The setpoint display is delivered with the factory-set Node-ID 125 (7Dh).

Control field:

Contains bit-by-bit information on the number of user data and decides whether a data frame or a Remote Transmission Request (RTR) frame is concerned.

Data field:

Contains up to 8 bytes of user data. The user data has a different meaning depending on the channel selection.

CRC:

Contains bits for error detection.

ACK/EOF:

The ACK/EOF field contains telegram acknowledgement bits as well as bits for determining the end of telegram.

For a detailed description of the telegram refer to the relevant CAN expert literature. For simplification, only identifier (COB-ID) and data field will be dealt with in the subsequent telegram descriptions.

5.2 Node control

5.2.1 Network management services (NMT)

The master configures, manages and monitors network nodes via the NMT service. The device is always in one of the four communication statuses "INITIALISATION", "PRE-OPERATIONAL", "OPERATIONAL" or "STOPPED" (see Fig. 5).

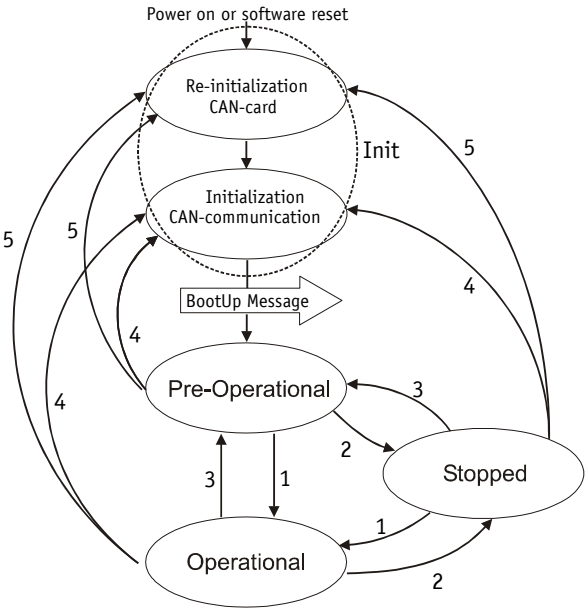

Fig. 5: NMT status diagram

5.2.1.1 NMT communication statuses

NMT Status INITIALIZATION

The unit is not involved in the bus actions in this state. All hardware and software components are initialised. This state is attained after switching on the device or after receipt of the command code 81h of the own or global addresses. After receiving the command code 82h, the display is also in the initialization status. However, only the hardware and software associated with CAN communication is reinitialized. The device automatically signifies completion of initialization via a boot-up message. After successful transmission of the boot-up message, the device will be in the "PRE-OPERATIONAL" status.

NMT Status PRE-OPERATIONAL

Parameterization data (SDO) can be exchanged in the Pre-Operational Mode. However, no process data (PDO) is transferred.

NMT Status OPERATIONAL

Exchange of process data is enabled as well.

NMT Status STOPPED

Communication is stopped except for Heartbeat and Node Guarding. Only NMT communication is enabled.

5.2.1.2 Switching between NMT communication states

Telegrams with the following structures are used for switching between the communication statuses:

Status change		Transition in Fig. 5	COB-ID	Com.	Node-ID
from	to				
PRE-OPERATIONAL / STOPPED	OPERATIONAL	1	0h	01h	x
OPERATIONAL/ PRE-OPERATIONAL	STOPPED	2	0h	02h	x
OPERATIONAL / STOPPED	PRE-OPERATIONAL	3	0h	80h	x
OPERATIONAL / PRE-OPERATIONAL / STOPPED	INITIALISATION (Reset Node)	5	0h	81h	x
OPERATIONAL / PRE-OPERATIONAL / STOPPED	INITIALISATION (Reset Communication)	4	0h	82h	x

Table 10: Switching between communication statuses

If transmitted as Node-ID x = 0, the message is intended for all bus subscribers.

5.2.2 Boot-Up

The COB-ID of the Boot-Up message consists of 700h and the Node-ID. The NMT-status "Initialization" is output as data content.

COB-ID	Byte 0
700h + Node-ID	00h

Table 11: Boot-up message

5.2.3 SYNC object

CANopen makes it possible to simultaneously scan inputs and simultaneously set outputs. This is accomplished by the synchronization message (SYNC), a high-priority CAN message. The identifier of the Sync object can be set via object 1005h (see 1005h: COB-ID SYNC message).

5.3 Process data exchange

5.3.1 Transfer of Process Data Objects (PDO)

Process data objects (PDO) serve for quick process data exchange. A maximum of 8 bytes of user data can be transferred in a PDO. AP10S supports the Receive-PDO services RPDO1 and RPDO2 according to Draft Standard 301 as well as the Transmit-PDO services TPDO1 and TPDO2 according to Draft Standard 301 and Device Profile 406.

5.3.1.1 Transmit PDO (from AP10S to the master)

PDO transfer from the display to the bus master (TPDO) can be initiated as a result of various events:

- asynchronous, controlled by an internal device timer
- synchronous as a reply to a SYNC message
- as a reply to an RTR message

TPDO1 and TPDO2 are always formed from a status word (see chapter 5.3.3: Status word) and the current position value.
The transfer behavior of TPDO1 is determined via objects 1800h, 1A00h and 6200h and is assigned to asynchronous transfer. TPDO2 is defined via objects 1801h and 1A01h and serves for synchronous transfer.

The messages have the structure shown in Table 12, and mapping cannot be changed.

COB-ID	Process data in binary code							
	Byte 0 (LSB)	Byte 1	Byte 2	Byte 3 (MSB)	Byte 4	Byte 5	Byte 6	Byte 7
TPDO1 180h + Node-ID	Position value				Dummy 0x0000		5F19h: Status word (see chapter 5.3.3)	
TPDO2 280h + Node-ID								

Table 12: TPDO message

Asynchronous data transfer (TPDO1)

If a TPDO1 is to be sent cyclically, then the cycle time must be entered into object 1800h, sub-index 5, in milliseconds. The TPDO1 will not be sent if the value 0 ms is written. The function is disabled. The minimum value to be set is 1 (=1 ms). Alternately, the value can also be written into the object 6200h which is permanently linked internally.

Synchronous data transfer (TPDO2)

The device is factory set to reply by output of the TPDO2 message when receiving a SYNC message. Thus it is set to the synchronous transfer type. 1 is entered in object 1801h, sub-index 2. The device responds to every n SYNC message if a value n between 1 and 240 (=F0h) has been entered.

RTR

Queries can be sent to TPDO1 and TPDO2 via RTR (see chapter 5.1: Telegram setup, Controlfield).

5.3.1.2 Receive-PDO (from master to AP10S)

Using Receive-PDO transfer (RPDO), setpoints and control commands (see chapter 5.3.2: Control word) can be transmitted from the bus master to the display.

COB-ID	Process data in binary code							
	Byte 0 (LSB)	Byte 1	Byte 2	Byte 3 (MSB)	Byte 4	Byte 5	Byte 6	Byte 7
RPDO1 200h + Node-ID	Target value 1				Data identifier equal to ASCII: Byte 4 and 5 of setpoint 1		5F0Ch: Control word (see chapter 5.3.2)	
					Otherwise dummy 0x0000			
RPDO2 300h + Node-ID	Target value 2				Data identifier equal to ASCII: Byte 4 and 5 of setpoint 2			
					Otherwise dummy 0x0000			

Table 13: RPDO message

The transfer behavior of RPDO1 is defined via objects 1400h and 1600h. RPDO2 is defined via objects 1401h and 1601h.
A differentiation is made between Setpoint1 und Setpoint2 only in the alpha-numeric display mode. Setpoint1 is displayed in the upper row and Setpoint2 in the lower row. In the position-dependent modes, the setpoint last received, if valid, is output in the 2nd row.

5.3.2 Control word

The control word consists of 16 bits and is mapped in the object 5F0Ch: Control word. This object is received with both Receive-PDOs.

Control word															
15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
MSB			High Byte					Low Byte							LSB

The following table lists the designations of the individual bits of the control word and their meanings.

Bit	Meaning	Value = 0	Value = 1
0	reserved	ever 0	-
1	reserved	ever 0	-
2	Validity of setpoint1	invalid	valid
3	Display range	standard	extended
4	Acknowledgment target window1 static	not acknowledged	acknowledged
5	Guarding Bit	is taken over	is taken over
6	With "Display" operating mode: Acknowledgement of setpoint2	not acknowledged	acknowledged
7	With "Display" operating mode: Data identifier	number	ASCII
8	reserved	ever 0	-
9	Validity of setpoint2	invalid	valid
10	With "Display" operating mode: Acknowledgement of setpoint1	not acknowledged	acknowledged
11	LED1 green left	Off	On
12	LED3 green right	Off	On
13	LED4 red right	Off	On
14	LED2 red left	Off	On
15	LED blinking	Off	On

Table 14: Control word

5.3.3 Status word

The status word indicates the current status of AP10S. It consists of 16 bits and is mapped in the object 5F19h: Status word as well as in the two Transmit-PDOs.

Status word															
15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
MSB			High Byte					Low Byte							LSB

The following table lists the designations of the individual bits of the status word and their meanings.

Bit	Meaning	Value = 0	Value = 1
0	Direction indication CW	OFF	ON
1	Direction indication CCW	OFF	ON
2	Validity setpoint1	invalid	valid
3	Target window2 dynamic	not reached	reached
	With "Display" operating mode: Acknowledgement of setpoint2	not acknowledged	acknowledged
4	Target window1 static	never reached	reached
5	Target window1 dynamic	not reached	reached
	With "Display" operating mode: Acknowledgement of setpoint1	not acknowledged	acknowledged
6	Deviation	actual position <= set point	actual position > set point
7	Battery empty (fault)	not present	is present
8	Guarding Bit	is output	is output
9	Position value = incremental measurement	OFF	ON
	With "Display" operating mode: Data identifier	number	ASCII-String
10	Validity setpoint2	invalid	valid
11	Battery status (warning)	all right	critical
12	Sensor error (Tape-Sensor or Lost-Sensor or Speed)	not present	is present
13	← key	not actuated	actuated
14	✱ key	not actuated	actuated
15	↑ key	not actuated	actuated

Table 15: Status word

5.4 Parameter data exchange

5.4.1 Transfer of Service data objects (SDO)

Service data objects serve mainly for device configuration via the directory of objects.

SDOs are exchanged between two participants exclusively via expedited Request/Response. User data is sent already with the initialization message. The identifier is set to 11 bits and cannot be changed.

Two SDO services are available:

- SDO (rx) (master → AP10S): 600h + Node-ID
- SDO (tx) (AP10S → master): 580h + Node-ID

These SDO identifiers cannot be changed!

SDO messages are set up as follows:

COB-ID	**User data in binary code**							
	Byte 0 read / write	**Byte 1 LSB**	**Byte 2 MSB**	**Byte 3**	**Byte 4 LSB**	**Byte 5**	**Byte 6**	**Byte 7 MSB**
SDO rx/tx + Node-ID	command	index		sub-index	service data (parameters)			

Command byte, Byte 0:

The command byte determines the type of access and the number of valid data bytes. The following command bytes are valid for AP10S:

Command byte		**Type**	**Function**
Write Request	23h	SDO (rx), Initiate Download Request, expedited	Send parameter to AP10S (all 4 data bytes valid)
Write Request	2Bh	SDO (rx), Initiate Download Request, expedited	Send parameter to AP10S (2 bytes from 4 data bytes valid)
Write Request	2Fh	SDO (rx), Initiate Download Request, expedited	Send parameter to AP10S (1 byte from 4 data bytes valid)
Write Response	60h	SDO (tx), Initiate Download Response	Acknowledgement of data acquisition to master
Read Request	40h	SDO (rx), Initiate Upload Request	Request parameter from AP10S
Read Response	43h	SDO (tx), Initiate Upload Response, expedited	Report parameter to master (all 4 data bytes valid)
Read Response	4Bh	SDO (tx), Initiate Upload Response, expedited	Report parameter to master (2 bytes from 4 data bytes valid)
Read Response	4Fh	SDO (tx), Initiate Upload Response, expedited	Report parameter to master (1 byte from 4 data bytes valid)
Error Response	80h	SDO (tx), Abort Domain Transfer	AP10S reports error code to master

Table 16: Command coding

Index, bytes 1 and 2:

The index (object number) is entered in user data byte 2 (low byte) and in in user data byte 3 (high byte) in the Intel data format. Here, the index of the object to be parameterized is entered.

Sub-index, byte 3:

The sub-index indicates the number of the fields for objects realized as an array.

Service data (Parameter), byte 4-7:

In the service data area, the value of the parameter is entered in left-aligned Intel notation.
Byte 4 = low-Byte ... Byte 7 = high Byte

5.4.1.1 Error Response

An error report (Abort) is returned to the master in case of invalid access.
The error codes are described in the CANopen profile (DS 301) or in the encoder profile (DSP 406), respectively. The following table shows the error codes used:

Error code	Description
06010000h	Wrong access to an object.
06010001h	Read access to Write-Only.
06010002h	Write access to Read-Only.
06020000h	Object doesn't exist in the object directory.
06090011h	Sub-index does not exist.
06090030h	Wrong value range of selected parameter.
08000020h	Parameters cannot be transferred to application or stored.
08000022h	Parameters cannot be transferred to application or stored due to the current device status.
08000024h	No data available

Table 17: Error code

Example of reading SDO parameters:

Read the calibration value stored in object 6003h of the directory of objects from AP10S with device address 1.

Calculation of the identifier: 600h + Node-ID = 600h +1h = 601h

Command: 40h
Index: 6003h
Sub-index: 00h
The current value is 510 = 01FEh

Query by master from slave with Node-ID 1:

COB-ID	User data							
	Command	Index L	Index H	Sub-index	Data 0	Data 1	Data 2	Data 3
601h	40h	03h	60h	00h	x	x	x	x

Response to the request by the slave:

Calculation of the identifier: 580h + Node-ID = 581h

COB-ID	User data							
	Command	Index LB	Index HB	Sub-index	Data 0	Data 1	Data 2	Data 3
581h	43h (4 bytes valid)	03h	60h	00h	FEh	01h	00h	00h

Example of writing SDO parameters:

Change the loop length stored with 2 bytes in object 5F14h of the directory of objects in the AP10S with device address 1.

Calculation of the identifier: 600h + Node-ID = 600h + 1 = 601h

Command: Write 2 bytes: 2Bh
Index: 5F14h
Sub-index: 00h
The new value shall be 4500 = 1194h

Mater to write a value to the slave with Node-ID 1:

COB-ID	User data							
	Command	Index L	Index H	Sub-index	Data 0	Data 1	Data 2	Data 3
601h	2Bh (2 bytes valid)	14h	5Fh	00h	94h	11h	00h	00h

Node monitoring:

Calculation of the identifier: 580h + Node-ID = 580h + 1 = 581h

COB-ID	User data							
	Command	Index L	Index H	Sub-index	Data 0	Data 1	Data 2	Data 3
581h	60h	14h	5Fh	00h	00h	00h	00h	00h

5.5 Node monitoring

5.5.1 Emergency Service (EMCY)

The status of the bus subscriber is transferred via high-priority emergency messages in case of error. These messages have a data length of 8 bytes and contain information on the error.

The emergency message is transferred as soon as a serious communication error occurred or was corrected. The cause of error is stored in the error buffer (see object 1003h: Pre-defined Error Field). An emergency object is sent only once per error event. Removal of a cause of error is signified by sending an emergency message with Error Code 0000h (No Error). If multiple errors exist and one cause of an error has been corrected, then Error Code 0000h is output as well; however, the persisting error condition is indicated in the Error Register.

Identifier	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
11/ 29 Bit	Emergency Error Code		Error Register (Object 1001h)	Manufacturer-specific error field (not used)				

Emergency Error Code:

Error description	Error Code
Cause of error removed	0x0000
Battery empty	0x3200
Bus status changed to Error Passive Mode	0x8120
Recovered from Bus Off	0x8140
Manufacturer-specific: Speed error	0xFF10
Manufacturer-specific: critical battery status	0xFF11
Cause of error removed	0xFF12
Battery empty	0xFF20

Table 18: Emergency Error Code

The identifier of the emergency object is set to 80h + Node-ID by default; however, it can be changed via object 1014 h (see 1014h: COB-ID Emergency Message). Transmission of an emergency message is only possible in the "OPERATIONAL" or "PRE-OPERATIONAL" NMT statuses.

5.5.2 Node Guarding

Node Guarding is available for failure monitoring of the CANopen network. During guarding, the master transmits remote frames (RTR, remote transmit request, request message) on the guarding identifiers of the nodes to be monitored. They respond with the Guarding message, which contains the current NMT status of the node as well as a toggle bit whose value must change with every message. If NMT status or toggle bit do not correspond with the value expected by the master or if there is no response, then the master assumes a node error.

Via objects 100Ch (Guard Time) 100Dh (Life Time Factor), the time interval (Life-Time) is set within which the NMT master expects to receive a message. The time interval "Life time" is calculated from the cycle time "Guard time" multiplied with the factor "Life Time Factor". If the NMT master receives no response to its RTR frame within the "Life-Time", it can react with appropriate measures. After switching on, Node Guarding is activating by the master sending the first RTR frame to the slave. If the value of either object (100Ch or 100Dh) is set to 0, Node Guarding will be deactivated.

The node's response to the master's RTR frame is formed as follows:

Identifier	Byte 0	
700h + Node-ID	Bit 7: toggle Bit	Bit 6 ... 0: NMT status

Toggle Bit:

The toggle bit must alternate between two subsequent responses of the unit. After activation of the Guarding protocol, the toggle bit must have the value 0 with the first response.

NMT status:

4: STOPPED

5: OPERATIONAL

127: PRE-OPERATIONAL

The identifier of the heartbeat protocol is permanently set to 700h + Node-ID and cannot be changed. Sending of a Node Guard message is possible in the "OPERATIONAL", "PREOPERATIONAL" or "STOPPED" NMT statuses.

5.5.3 Heartbeat

The master monitors the status of the slave device via the Heartbeat protocol. While doing this, the unit sends cyclically its NMT status. The AP10S is a heartbeat producer, it does not receive nor process heartbeat protocols. The cycle time of the heartbeat message is set via object 1017h. The heartbeat protocol is inactivated if the cycle time is 0.

The heartbeat message consists of the COB-ID and an additional byte, which is used to store the current NMT status.

COB-ID	Byte 0
700h + Node-ID	NMT status

NMT status:

4: STOPPED

5: OPERATIONAL

127: PRE-OPERATIONAL

The identifier of the heartbeat protocol is permanently set to 700h + Node-ID and cannot be changed. Sending of a Node Guard message is possible in the "OPERATIONAL", "PREOPERATIONAL" or "STOPPED" NMT statuses.

5.5.4 External heartbeat

In addition to the function described under Heartbeat, the NMT status can be controlled via the external heartbeat. In this case, a value corresponding to an interval in ms is entered in object 5F09h sub-index 1. If the devices receives no external heartbeat message during this interval, the display will switch over to Pre-Operational status. The type of message to be interpreted as external heartbeat is set in object 5F09h sub-index 2. The value 0 means that the timer is triggered when receiving an RPDO (setpoint). With value 1, the timer is triggered when receiving a SYNC (see object 5F09h: External Heartbeat timer and external Heartbeat source).

5.5.5 Guarding Bit

There is a guarding bit in the control word, which serves for monitoring communication or the NMT state of the device, respectively. When receiving the control word, the content of this bit will be copied into the guarding bit of the status word and output with the next TPDO. Thus, by shifting the bit in the control word, the superordinate control can verify without additional data traffic that process data exchange is in operation. This function is especially helpful when a gateway (converter from CANOpen to superordinate fieldbus) is used.

5.6 Auto functions

5.6.1 Auto-Baud

This function facilitates first commissioning of the devices in the plant. The baud rate is factory-set to "Auto Baud". AP10S "overhears" the bus and does not transmit messages. To enable the instrument's autonomous recognition and adjustment of the prevalent bus baud rate, communication must take place on the CAN bus. If the device recognizes a faultless message with the internally set baud rate it will be adopted as a valid baud rate, CAN initialization finished and a boot-up message sent. If no message is detected till expiry of the dwell time, then the next valid baud rate is set and checked for communication. The search for a baud rate is not stopped until a valid baud rate has been found. If the baud rate is to be adopted permanently, it must be saved upon command (see chapter 5.7.2.11: 1010h: Store Parameter).

The Auto Baud function can be activated or deactivated during parameterization (see chapter 4.3: Parameterization of the position indicator) and the desired baud rate directly set.

5.6.2 Auto-ID

5.6.3 Auto-ID

This function facilitates first commissioning of the devices in the plant. The node numbers can be assigned by the superordinate control or by pressing the relevant button on the device concerned.

The Node ID 7Dh (125d) is factory-set. After finishing initialization, every device sends a boot-up message and switches over to the "PRE-OPERATIONAL" status. Now, the CAN master must send to the bus subscriber(s) with the current Node-ID 7Dh an SDO message to object 5F0Ah sub-index 2 with the new Node ID to be set and await an SDO reply.

"New ID" will be displayed on all devices that have the current Node-ID 7Dh. The user must press the ↑ key on the device intended to adopt the new Node ID. Subsequently, this device will send an SDO reply with the identifier 5FDh. The new Node-ID is taken over and stored in the EEPROM. The initialization phase is run again and a boot-up message sent with the new Node-ID. All other devices do not react. Afterwards, the control execute a reset of all nodes for example in order to find out whether there are still devices in the bus with Node-ID 7Dh. If so, the procedure may be repeated until all devices have received the desired Node-ID. The Auto-ID function is aborted in the AP10S when an illegal value was sent for the new ID. SDO Abort messages will be returned in this case.

Use of this function is optional. The node numbers can also be set via parameterization (see chapter 4.3: Parameterization of the position indicator).

COB-ID	Byte 0	Byte 1 (LSB)	Byte 2 (MSB)	Byte 3	Byte 4 (LSB)	Byte 5	Byte 6	Byte 7 (MSB)
67Dh	2Fh	0Ah	5Fh	02h	New Node-ID	x	x	x

Table 19: Auto-ID: SDO-message from the master

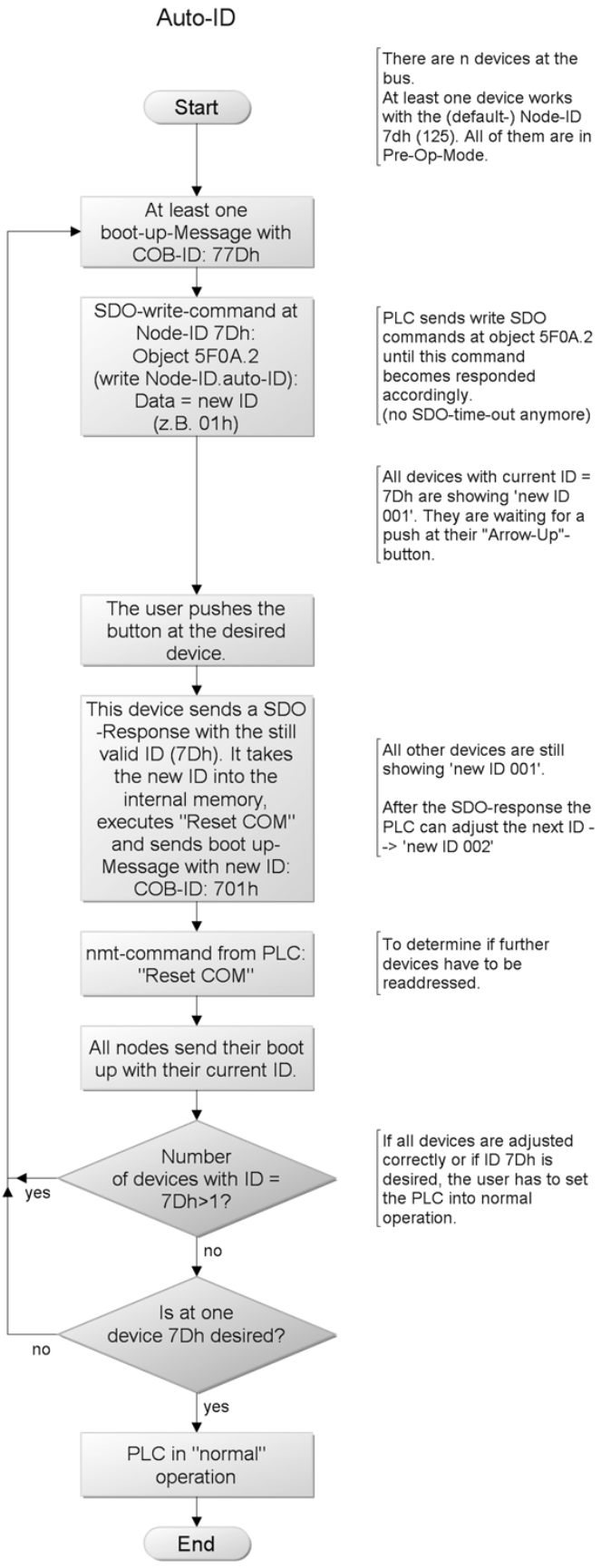
Auto-ID
There are n devices at the bus.
At least one device works with the (default-) Node-ID 7dh (125). All of them are in Pre-Op-Mode.
Start
At least one boot-up-Message with COB-ID: 77Dh
SDO-write-command at Node-ID 7Dh: Object 5F0A.2 (write Node-ID.auto-ID): Data = new ID (z.B. 01h)
PLC sends write SDO commands at object 5F0A.2 until this command becomes responded accordingly.
(no SDO-time-out anymore)
All devices with current ID = 7Dh are showing 'new ID 001'. They are waiting for a push at their "Arrow-Up"-button.
The user pushes the button at the desired device.
This device sends a SDO -Response with the still valid ID (7Dh). It takes the new ID into the internal memory, executes "Reset COM" and sends boot up-Message with new ID: COB-ID: 701h
All other devices are still showing 'new ID 001'.
After the SDO-response the PLC can adjust the next ID -> 'new ID 002'
nmt-command from PLC: "Reset COM"
To determine if further devices have to be readdressed.
All nodes send their boot up with their current ID.
Number of devices with ID = 7Dh>1?
yes
no
If all devices are adjusted correctly or if ID 7Dh is desired, the user has to set the PLC into normal operation.
Is at one device 7Dh desired?
no
yes
PLC in "normal" operation
End

Fig. 6: Auto-ID function

5.7 Directory of objects

5.7.1 Overview of objects

The following table offers an overview of the objects of the unit.

Name	Description	see page
1000h: Device Type	Device profile and encoder type.	36
1001h: Error Register	Current error state of the device.	36
1002h: Manufacturer Status Register	Contains the Receive Error Counter and the Transmit Error Counter.	37
1003h: Pre-defined Error Field	The object stores the 8 error states that have occurred last.	37
1005h: COB-ID SYNC message	Setting of the COB ID of the SYNC object.	38
1008h: Manufacturer Device Name	Device name in in ASCII characters	38
1009h: Manufacturer Hardware Version	Indicates the hardware version of the device.	39
100Ah: Manufacturer Software Version	Indicates the software version of the device.	39
100Ch: Guard Time	Parameter for Node Guarding.	39
100Dh: Life Time Factor	Parameter for Node Guarding.	40
1010h: Store Parameter	Object for non-volatile storage of the settings.	40
1011h: Restore Parameter	Object for restoring the factory settings.	42
1014h: COB-ID Emergency Message	COB ID of the Emergency message.	44
1017h: Producer Heartbeat Time	Setting of the cycle time of the heartbeat timer.	45
1018h: Identity Object	Contains the manufacturer number assigned by CiA.	45
1200h: Server SDO Parameter	SDO parameter	46
1400h: 1. Receive PDO Parameter	Receive PDO1	47
1401h: 2. Receive PDO Parameter	Receive PDO2	48
1600h: 1. Receive PDO Mapping Parameter	Describes the arrangement of the objects mapped in RPDO1.	49
1601h: 2. Receive PDO Mapping Parameter	Describes the arrangement of the objects mapped in RPDO2.	50
1800h: 1. Transmit PDO Parameter	Transmit PDO for asynchronous transmission (timer-controlled).	51
1801h: 2. Transmit PDO Parameter	Transmit PDO for synchronous transmission.	53
1A00h: 1. Transmit PDO Mapping Parameter	Describes the arrangement of the objects mapped in TPDO1.	54
1A01h: 2. Transmit PDO Mapping Parameter	Describes the arrangement of the objects mapped in TPDO2.	55
2001h: Manufacturer Offset	Manufacturer-specific offset value (is added to the position value encoder-internally).	56
2002h: Calibrate encoder value	Set the position value to the calibration value.	57

Name	Description	see page
2003h: Calibration enable	Setting whether calibration of the display is enabled via key actuation.	57
2004h: Incremental measurement enable	Setting whether setting of the incremental measurement function is enabled via key actuation.	58
2005h: Configuration enable via keyboard and delay of start of configuration	Setting whether configuration is enabled via key operation. Delay of start of configuration.	58
5000h: Diagnosis of CAN bus errors	Informs about CAN bus error events.	59
5F09h: External Heartbeat timer and external Heartbeat source	Cycle time and trigger source of the external heartbeat.	59
5F0Ah: Node-ID, Auto-ID and Baud rate Bus CAN	Setting of Node-ID baud rate.	60
5F0Bh: Display in the 2nd row	Setting of the display in the 2nd row.	62
5F0Ch: Control word	Control word	62
5F0Dh: Differential value and difference formation	Differential value and setting of difference formation.	62
5F10h: Target window1 (near field)	Setting of target window1 (close-up range).	63
5F11h: Decimal places	Number of decimal places.	64
5F12h: Display orientation and LEDs	Setting of the display orientation and LED functionality.	64
5F13h: Display divisor (ADI) and ADI application	Setting of the display divisor and its application.	67
5F14h: Loop length	Setting of the loop length.	68
5F15h: Positioning type	Setting of the loop type's direction of approach.	68
5F16h: Read target value	Read current target value; write access only via PDO.	68
5F17h: Period counter, sensor ADC values and absolute fine value	Outputs the following current values: Period counter, sensor ADC values and absolute fine value.	70
5F19h: Status word	Output of the device status.	71
5F1Bh: Sensor type and operating mode	Reading sensor type and setting of the operating mode (absolute, differential display, 360°, alpha-numeric display).	71
5F1Ch: Acknowledgement settings	Setting of the key to be used as acknowledgement key (alpha-num. display).	72
5F1Fh: Direction indicators (CW, CCW)	Setting of the appearance of the direction arrows.	72
5F21h: Target window2 (far) and target window2 visualization	Setting of target window2 and its visualization.	73
6000h: Operating Parameters	Setting of scaling and sense of rotation.	74
6001h: Measuring steps per revolution (Display per revolution = APU)	Setting of the measuring steps per revolution displayed (Display per revolution = APU).	75
6002h: Total of measuring steps	Indicates the total of measuring steps of the system.	75

Name	Description	see page
6003h: Preset value (calibration value)	Setting of the calibration value.	75
6004h: Position value	Position value (offset against calibration and offset value)	76
6005h: Resolution	Only for MS500H: Setting of the resolution.	76
6200h: Cycle Timer	Identical with object 1800h, sub-index 5.	77
6500h: Operating Status	Output of scaling and sense of rotation.	77
6501h: Single-turn resolution	Indicates the physical number of measuring steps per revolution.	78
6502h: Number of distinguishable revolutions	Indicates the number of revolutions the encoder is able to scan.	78
6503h: Alarms	Indication of error states.	78
6504h: Supported Alarms	Indicates which alarm messages are supported.	79
6505h: Warnings	Indication of warnings.	79
6506h: Supported Warnings	Indicates which warnings are supported.	80
6507h: Profile and Software Version	Indicates the version number of the device profile used and the version number of the encoder's firmware.	80
6508h: Operating Time	Counter of operating hours (function is not supported)	80
6509h: Encoder calibration value	Encoder status at the time of calibration.	81
650Ah: Module Identification	Indicates the offset value as well as the smallest and largest transferable position value.	81
650Bh: Serial Number	Outputs the value FFFFFFFFh (function is not supported).	82

Table 20: Overview of objects

5.7.2 Description of objects

5.7.2.1 1000h: Device Type

Object 1000h indicates the device profile number.

Sub-index	00h			
Description	Information on device profile and device type			
Access	ro			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	00030196h			
EEPROM	no			
Data content	Device profile number		Encoder type	
	Byte 0	Byte 1	Byte 2	Byte 3
	96h	01h	GS04: 05h MS500H: 07h	00h

0196h (= 406): CANopen Device Profile for Encoders, Version 3.02

0007h: with MS500H connected: Incremental linear encoder, with battery-buffered electronic period counter

0005h: with GS04 connected: Incremental rotative encoder, with battery-buffered electronic period counter

5.7.2.2 1001h: Error Register

Object 1001h indicates the error state of the device.

Sub-index	00h	
Description	currently existing error status	
Access	ro	
PDO mapping	no	
Data type	UNSIGNED 8	
Default	0x00	
EEPROM	no	
Data content	Bit	Meaning
	0	set bit indicates the occurrence of any error condition
	4	set bit indicates communication error on the CAN bus (Acknowledgement-, Form-, CRC- and Stuffbit)
	7	manufacturer-specific (battery or sensor error)
	1-3, 5-6	not used

Faults and errors are signalled at the time of their occurrence by an emergency message.

5.7.2.3 1002h: Manufacturer Status Register

The object 1002h shows the counter readings of "Transmit Error Counter" and "Receive Error Counter". The contents of these registers provide information on the transmit faults present at the mounting site of the encoder.

Sub-index	00h			
Description	Transmit Error Counter and Receive Error Counter			
Access	ro			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	0x0000			
EEPROM	no			
Data content	Byte 0	Byte 1	Byte 2	Byte 3
	Receive Error Counter	Transmit Error Counter		

5.7.2.4 1003h: Pre-defined Error Field

The 8 error states that occurred last are archived in object 1003h (see chapter 5.5.1: Emergency Service (EMCY)).

- The entry under sub-index 0 indicates the number of stored errors.
- The latest error state is always stored in sub-index 1. Previous error messages are each shifted one sub-index position farther.
- The whole error list is deleted by writing the value 0 at sub-index 0.
- The entries in the error list have the format described in chapter 5.5.1: Emergency Service (EMCY).

Sub-index	00h
Description	number of the error messages stored
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0
EEPROM	yes

Sub-index	01h-08h
Description	error messages that occurred
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0
EEPROM	yes

5.7.2.5 1005h: COB-ID SYNC message

The COB-ID of the SYNC object is set via object 1005h.

Sub-index	00h	
Description	Defines the COB ID of the synchronization object (SYNC)	
Access	rw (writable in the "Pre-Operational" state only see chapter 5.1)	
PDO mapping	no	
Data type	UNSIGNED 32	
Default	80h	
EEPROM	yes	
Data content	Bit 31	not defined
	Bit 30	0: unit generates no SYNC message
	Bit 29	0: 11bit identifier (CAN 2.0A) 1: 29bit identifier (CAN 2.0B)
	Bit 28 ... 11	0: if bit 29 = 0 X: bits 28 – 11 of the SYNC-COB-ID, if bit 29 = 1
	Bit 10 ... 0	X: bits 10 – 0 of the SYNC-COB-ID

5.7.2.6 1008h: Manufacturer Device Name

Object 1008h indicates the device name.

Sub-index	00h			
Description	Device name as ASCII characters			
Access	Const			
PDO mapping	no			
Data type	Visible_String			
Default	AP10S			
EEPROM	no			
Data content	Byte 0	Byte 1	Byte 2	Byte 3
	41h ("A")	50h ("P")	31h ("1")	30h ("0")

5.7.2.7 1009h: Manufacturer Hardware Version

Object 1009h indicates the hardware version.

Sub-index	00h			
Description	Hardware version as ASCII characters			
Access	Const			
PDO mapping	no			
Data type	Visible_String			
Default	V001			
EEPROM	no			
Data content	Byte 0	Byte 1	Byte 2	Byte 3
	56h ("V")	30h ("0")	30h ("0")	31h ("1")

5.7.2.8 100Ah: Manufacturer Software Version

Object 100Ah indicates the software version of the device.

Sub-index	00h			
Description	Software version as ASCII characters			
Access	Const			
PDO mapping	no			
Data type	Visible_String			
Default	V100			
EEPROM	no			
Data content	Byte 0	Byte 1	Byte 2	Byte 3
	56h ("V")	31h ("1")	30h ("0")	30h ("0")

5.7.2.9 100Ch: Guard Time

The object 100Ch indicates the cycle time set in the master for Node Guarding (see chapter 5.5.2: Node Guarding). The cycle time is indicated in milliseconds. The value "0" means that Node Guarding is deactivated.

Sub-index	00h
Description	Guard Time
Access	rw
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	yes

5.7.2.10 100Dh: Life Time Factor

The object 100Dh indicates the Life Time Factor set in the master for Node Guarding (see chapter 5.5.2: Node Guarding). The value "0" means that Node Guarding is deactivated.

Sub-index	00h
Description	Life Time Factor
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes

5.7.2.11 1010h: Store Parameter

With this objects, parameter are transferred into the EEPROM in order to be available in case of voltage failure. Different parameter groups are saved depending on the sub-index selected for access. The string "save" as data content must also be sent.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	4h
EEPROM	no

Subindex	01h			
Description	save all parameters			
Access	rw			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	1h			
EEPROM	no			
Data content	Write:			
	Byte 0	Byte 1	Byte 2	Byte 3
	73h ("s")	61h ("a")	76h ("v")	65h ("e")
	Read:			
	Bit 31 ... 2	0, reserved		
	Bit 1	0: device does not save parameters autonomously		
	Bit 0	1: unit stores parameter by command		

Sub-index	02h			
Description	save only communication parameters (1000h-1FFFh, DS301)			
Access	rw			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	1h			
EEPROM	no			
Data content	Write:			
	Byte 0	Byte 1	Byte 2	Byte 3
	73h ("s")	61h ("a")	76h ("v")	65h ("e")
	Read:			
	Bit 31 ... 2	0, reserved		
	Bit 1	0: device does not save parameters autonomously		
	Bit 0	1: unit stores parameter by command		

Sub-index	03h			
Description	save only application parameters (6000h-9FFFh, DS406)			
Access	rw			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	1h			
EEPROM	no			
Data content	Write:			
	Byte 0	Byte 1	Byte 2	Byte 3
	73h ("s")	61h ("a")	76h ("v")	65h ("e")
	Read:			
	Bit 31 ... 2	0, reserved		
	Bit 1	0: device does not save parameters autonomously		
	Bit 0	1: unit stores parameter by command		

Sub-index	04h			
Description	save only manufacturer-specific parameters (2000h-5FFFh)			
Access	rw			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	1h			
EEPROM	no			
Data content	Write:			
	Byte 0	Byte 1	Byte 2	Byte 3
	73h ("s")	61h ("a")	76h ("v")	65h ("e")
	Read:			
	Bit 31 ... 2	0, reserved		
	Bit 1	0: device does not save parameters autonomously		
	Bit 0	1: unit stores parameter by command		

5.7.2.12 1011h: Restore Parameter

The object 1011h restores the factory settings of the device depending on the selection. The string "load" must be sent as data content and reset executed afterwards. If the restored parameters must be available permanently, they must be saved via object 1010h: Store Parameter.

Sub-index	00h
Description	indicates the largest supported sub-index
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	4h
EEPROM	no

Sub-index	01h			
Description	reset all parameters to factory settings			
Access	rw			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	1h			
EEPROM	no			
Data content	Write:			
	Byte 0	Byte 1	Byte 2	Byte 3
	6Ch ("l")	6Fh ("o")	61h ("a")	64h ("d")
	Read:			
	Bit 31 ... 1	0, reserved		
	Bit 0	1: unit permits loading of default parameters		

Sub-index	02h			
Description	reset only communication parameters to factory settings			
Access	rw			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	1h			
EEPROM	no			
Data content	Write:			
	Byte 0	Byte 1	Byte 2	Byte 3
	6Ch ("l")	6Fh ("o")	61h ("a")	64h ("d")
	Read:			
	Bit 31 ... 1	0, reserved		
	Bit 0	1: unit permits loading of default parameters		

Sub-index	03h			
Description	reset only communication parameters to factory settings			
Access	rw			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	1h			
EEPROM	no			
Data content	Write:			
	Byte 0	Byte 1	Byte 2	Byte 3
	6Ch ("l")	6Fh ("o")	61h ("a")	64h ("d")
	Read:			
	Bit 31 ... 1	0, reserved		
	Bit 0	1: unit permits loading of default parameters		

Sub-index	04h			
Description	reset only manufacturer-specific parameters to factory settings			
Access	rw			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	1h			
EEPROM	no			
Data content	Write:			
	Byte 0	Byte 1	Byte 2	Byte 3
	6Ch ("l")	6Fh ("o")	61h ("a")	64h ("d")
	Read:			
	Bit 31 ... 1	0, reserved		
	Bit 0	1: unit permits loading of default parameters		

5.7.2.13 1014h: COB-ID Emergency Message

The COB-ID of the Emergency object is set via object 1014h (see chapter 5.5.1: Emergency Service (EMCY)).

Sub-index	00h	
Description	Defines the COB ID of the Emergency object (EMCY)	
Access	rw (writable in the "Pre-Operational" state only see chapter 5.2: Node control)	
PDO mapping	no	
Data type	UNSIGNED 32	
Default	80h + Node-ID	
EEPROM	yes	
Data content	Bit 31	0: EMCY object exists / is valid 1: EMCY object does not exists / is invalid
	Bit 30	ever 0
	Bit 29	0: 11bit identifier (CAN 2.0A) 1: 29bit identifier (CAN 2.0B)
	Bit 28 ... 11	0: if bit 29 = 0 X: bits 28 – 11 of the EMCY-COB-ID, if bit 29 = 1
	Bit 10 ... 0	X: bits 10 – 0 of the EMCY -COB-ID

5.7.2.14 1017h: Producer Heartbeat Time

The cycle time "Heartbeat Time" for the heartbeat protocol is set via object 1017h. The cycle time is indicated in milliseconds.

Sub-index	00h
Description	defines the cycle time of the heartbeat monitoring service
Access	rw
PDO mapping	no
Data type	UNSIGNED 16
Default	0
EEPROM	yes
Data content	0, 10 ... 65535 (0h, Ah ... FFFFh); the numerical value corresponds to a multiple of 1 ms. The value 0 deactivates the service.

5.7.2.15 1018h: Identity Object

The manufacturer identification number (Vendor ID) is indicated via object 1018h.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	4h
EEPROM	no

Sub-index	01h
Description	the manufacturer identification number (vendor ID) for the company SIKO GmbH allocated by the CiA
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	195h
EEPROM	no

Sub-index	02h
Description	Product Code (function is not supported, only compatibility entry for various configurators)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0h
EEPROM	no

Sub-index	03h
Description	Revision Number (function is not supported, only compatibility entry for various configurators)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0h
EEPROM	no

Sub-index	04h
Description	Serial Number (function is not supported, only compatibility entry for various configurators)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	FFFF FFFFh
EEPROM	no

5.7.2.16 1200h: Server SDO Parameter

The COB IDs for the Default Server SDO are indicated via object 1200h. The COB-IDs cannot be changed.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	2h
EEPROM	no

Sub-index	01h
Description	COB-ID Client -> Server (rx)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	00000600h + Node-ID
EEPROM	no

Sub-index	02h
Description	COB-ID Server -> Client (tx)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	00000580h + Node-ID
EEPROM	no

5.7.2.17 1400h: 1. Receive PDO Parameter

The communication parameters of the first Receive PDO (RPDO1) are set via object 1400h.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	5h
EEPROM	no

Sub-index	01h
Description	COB-ID des PDO1
Access	rw (writable in the "Pre-Operational" state only see chapter 5.1: Telegram setup)
PDO mapping	no
Data type	UNSIGNED 32
Default	200h + Node-ID
EEPROM	yes

Sub-index	02h
Description	Transmission Type
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	FFh
EEPROM	yes
Data content	0h ... F0h, FEh, FFh

Sub-index	03h
Description	Inhibit time (function is not supported, only compatibility entry for various configurators)
Access	ro
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	no

Sub-index	04h (is not used, access attempt generates error message)

Sub-index	05h
Description	Event timer (function is not supported, only compatibility entry for various configurators)
Access	ro
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	no

5.7.2.18 1401h: 2. Receive PDO Parameter

The communication parameters of the second Receive-PDOs (RPDO2) are set via object 1401h.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	5h
EEPROM	no

Sub-index	01h
Description	COB-ID of the PDO2
Access	rw (writable in the "Pre-Operational" state only see chapter 5.1)
PDO mapping	no
Data type	UNSIGNED 32
Default	300h + Node-ID
EEPROM	yes

Sub-index	02h

Description	Transmission Type
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	FFh
EEPROM	yes
Data content	0h ... F0h, FEh, FFh

Sub-index	03h
Description	Inhibit time (function is not supported, only compatibility entry for various configurators)
Access	ro
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	no

Sub-index	04h (is not used, access attempt generates error message)

Sub-index	05h
Description	Event timer (function is not supported, only compatibility entry for various configurators)
Access	ro
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	no

5.7.2.19 1600h: 1. Receive PDO Mapping Parameter

Object 1600h determines the objects that are mapped on the first Receive PDO (RPDO1).

Sub-index	00h
Description	number of objects mapped
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	3h
EEPROM	no

Sub-index	01h
Description	1st object of the PD01 message (Data byte 0 until 3)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0x5F160320 (Setpoint object 5F16h, Sub-index 0x03, 32bit)
EEPROM	no

Sub-index	02h
Description	2nd object of the PD01 message (Data byte 4+5)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0x5F160410 (Setpoint object 5F16h, Sub-index 0x04, 16bit)
EEPROM	no

Sub-index	03h
Description	3rd object of the PD01 message (Data byte 6+7)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0x5F0C0010 (Control word object 5F0Ch, Sub-index 0x00, 16bit)
EEPROM	no

5.7.2.20 1601h: 2. Receive PDO Mapping Parameter

Object 1601h determines the objects that are mapped on the second Receive PDO (RPD02).

Sub-index	00h
Description	number of objects mapped
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	3h
EEPROM	no

Sub-index	01h
Description	1st object of the PDO2 message (Data byte 0 until 3)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0x5F160120 (Setpoint object 5F16h, Sub-index 0x01, 32bit)
EEPROM	no

Sub-index	02h
Description	2nd object of the PDO2 message (Data byte 4+5)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0x5F160210 (Setpoint object 5F16h, Sub-index 0x02, 16bit)
EEPROM	no

Sub-index	03h
Description	3rd object of the PDO2 message (Data byte 6+7)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0x5F0C0010 (Control word object 5F0Ch, Sub-index 0x00, 16bit)
EEPROM	no

5.7.2.21 1800h: 1. Transmit PDO Parameter

According to DS406, TPDO1 is used for asynchronous PDO transmission.
The communication parameters are set for TPDO1 via object 1800h.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	5h
EEPROM	no

Sub-index	01h
Description	COB-ID des PDO1
Access	rw (writable in the "Pre-Operational" state only see chapter 5.1)
PDO mapping	no
Data type	UNSIGNED 32
Default	180h + Node-ID
EEPROM	yes

Sub-index	02h	
Description	Transmission Type	
Access	rw	
PDO mapping	no	
Data type	UNSIGNED 8	
Default	FEh (254)	
EEPROM	yes	
Data content	FEh (254) FFh (255)	PDO has asynchronous characteristics (PDO is sent depending on the "Event Timer").
	FDh (253)	Device responds to RTR-request only if RTR Bit 30 is enabled in the COB-ID.

Sub-index	03h
Description	Inhibit time (function is not supported, only compatibility entry for various configurators)
Access	ro
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	no

Sub-index	04h (is not used, access attempt generates error message)

Sub-index	05h
Description	event timer for TPDO1 hard-wired (DS406) with cyclic timer 6200h
Access	rw
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	yes
Data content	The service is disabled by writing the value 0. The content of this object is identical with object 6200h. If the value is changed while the timer is running, then the change will take effect only with the next timer run.

Sub-index	06h (is not used, access attempt generates error message)

5.7.2.22 1801h: 2. Transmit PDO Parameter

According to DS406, TPDO2 is used for synchronous PDO transmission.
The communication parameters are set for TPDO2 via object 1801h.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	5h
EEPROM	no

Sub-index	01h
Description	COB-ID of the PDO2
Access	rw (writable in the "Pre-Operational" state only see chapter 5.1)
PDO mapping	no
Data type	UNSIGNED 32
Default	280h + Node-ID
EEPROM	yes

Sub-index	02h	
Description	Transmission Type	
Access	rw	
PDO mapping	no	
Data type	UNSIGNED 8	
Default	1h	
EEPROM	yes	
Data content	FEh (254) FFh (255)	PDO is sent after receipt of 1 ... 240 SYNC messages.
	FDh (253)	Device responds to RTR-request only if RTR Bit 30 is enabled in the COB-ID.

Sub-index	03h
Description	Inhibit time (function is not supported, only compatibility entry for various configurators)
Access	ro
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	no

Sub-index	04h (is not used, access attempt generates error message)

Sub-index	05h
Description	Event timer (function is not supported, only compatibility entry for various configurators)
Access	ro
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	no

Sub-index	06h (is not used, access attempt generates error message)

5.7.2.23 1A00h: 1. Transmit PDO Mapping Parameter

Object 1A00h determines the objects that are mapped on the first Transmit PDO (TPDO1).

Sub-index	00h
Description	number of objects mapped
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	2h
EEPROM	no

Sub-index	01h
Description	1st object of the PDO1 message (Data byte 0 until 3)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	60040020h (Position value object 6004h, Sub-index 0x00, 32bit)
EEPROM	no

Sub-index	02h
Description	2nd object of the PDO1 message (Data byte 4+5)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	5F1D0010h (Dummy object 5F1D, Sub-index 0x00, 16bit)
EEPROM	no

Sub-index	03h
Description	3rd object of the PDO1 message (Data byte 6+7)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	5F190010h (Status word object 5F19h, Sub-index 0x00, 16bit)
EEPROM	no

5.7.2.24 1A01h: 2. Transmit PDO Mapping Parameter

Object 1A01h determines the objects that are mapped on the second Receive PDOs (TPDO2).

Sub-index	00h
Description	number of objects mapped
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	2h
EEPROM	no

Sub-index	01h
Description	1st Object of the PDO2 message (Data byte 0 until 3)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0x60040020 (Position value object 6004h, Sub-index 0x00, 32bit)
EEPROM	no

Sub-index	02h
Description	2nd Object of the PDO2 message (Data byte 4+5)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	5F1D0010h (Dummy object 5F1D, Sub-index 0x00, 16bit)
EEPROM	no

Sub-index	03h
Description	3rd Object of the PDO2 message (Data byte 6+7)
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	5F190010h (Status word object 5F19h, Sub-index 0x00, 16bit)
EEPROM	no

5.7.2.25 2001h: Manufacturer Offset

The offset value is determined via object 2001h.

Sub-index	00h
Description	The offset enables the shifting of a scaled value range. The offset value is added to the position value in the encoder. Positive as well as negative values are permitted. Position value = measured value + calibration value + offset value
Access	rw
PDO mapping	no
Data type	SIGNED 16
Default	0h
EEPROM	yes
Data content	-9999 ... 9999

5.7.2.26 2002h: Calibrate encoder value

Via object 2002h, calibration can be executed or information given whether calibration was executed.

Sub-index	00h	
Description	The object enables "zeroing" of the measured value. The position value is set to the calibration value thereby. Position value = measured value + calibration value + offset value	
Access	rw	
PDO mapping	no	
Data type	UNSIGNED 8	
Default	0h	
EEPROM	yes	
Data content	Object 2002h read:	
	0, 2	2 is fed back with a read access if calibration took place beforehand.
	Object 2002h write:	
	1	Writing the value 1 sets the position value to the calibration value.

5.7.2.27 2003h: Calibration enable

The object 2003h indicates whether calibration of the position value is enabled via key actuation.

Sub-index	00h
Description	key enable
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	1h
EEPROM	ja
Data content	0: Calibration disabled 1: Calibration enabled

5.7.2.28 2004h: Incremental measurement enable

The object 2004h indicates whether setting of the position value as incremental measurement is enabled via key actuation.

Sub-index	00h
Description	key enable
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	1h
EEPROM	yes
Data content	0: Incremental measurement disabled 1: Incremental measurement enabled

5.7.2.29 2005h: Configuration enable via keyboard and delay of start of configuration

Object 2005h indicates whether configuration via key actuation is enabled. The delay of start of configuration is set in sub-index 2 (key enable time).

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	2h
EEPROM	no

Sub-index	01h
Description	key enable
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	1h
EEPROM	yes
Data content	0: disabled (is not supported) 1: enabled

Sub-index	02h
Description	delay of start of configuration (key enable time)
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	5h
EEPROM	yes
Data content	1 ... 60 s

5.7.2.30 5000h: Diagnosis of CAN bus errors

A prioritized list of CAN bus errors occurring can be read via object 5000h.

Sub-index	00h			
Description	Indicates the CAN Bus errors Acknowledge, Form, CRC and Stuff Error sorted by frequency.			
Access	ro			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	0h			
EEPROM	no			
Data content	Byte 0	Byte 1	Byte 2	Byte 3
	General Acknowledgement error	Form error	CRC error	Stuff error
	0, 1, 2, 3, 4	0, 1, 2, 3, 4	0, 1, 2, 3, 4	0, 1, 2, 3, 4

Explanation of the data content:

0: Error does not occur at all

4: Error occurs most frequently

5.7.2.31 5F09h: External Heartbeat timer and external Heartbeat source

Via object 5F09h, an external heartbeat timer and its trigger source can be set. This function serves for monitoring the connection of the device to the master via CAN bus.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	2h
EEPROM	no

Sub-index	01h
Description	With a value greater than zero entered here, an event depending on the external heartbeat source set in sub-index 2 is expected in this interval. If no such event is received, the device will return to the "Pre-Operational" status.
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0, 10 ... 65535 (Ah ... FFFFh); the numerical value corresponds to a multiple of 1 ms. The function is disabled by writing the value 0.

Sub-index	02h
Description	source that triggers the external heartbeat timer in sub-index 1
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0: Timer is triggered upon receipt of a PDO (setpoint) 1: Timer is triggered upon receipt of a SYNC

5.7.2.32 5F0Ah: Node-ID, Auto-ID and Baud rate Bus CAN

Via object 5F0Ah, Node-ID, Auto-ID (see chapter 5.6.2: Auto-ID) and the baud rate of the bus (see chapter 5.6: Auto functions) can be set.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	3h
EEPROM	no

Sub-index	01h
Description	Node-ID
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	7Dh (125)
EEPROM	yes
Data content	1 ... 7Fh

Sub-index	02h
Description	Node-ID for access via Auto-ID function
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	
EEPROM	yes
Data content	1 ... 7Fh

Sub-index	03h
Description	baud rate of the CAN bus
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0 (Auto baud)
EEPROM	yes
Data content	0: Auto baud 1: 125 kbaud 2: 250 kbaud 3: 500 kbaud 4: 800 kbaud 5: 1000 kbaud

5.7.2.33 5F0Bh: Display in the 2nd row

Via object 5F0Bh the display of the 2nd row of the display unit is controlled. The setting is not effective in the "Display" operating mode.

Sub-index	00h
Description	controls the display of the 2nd row of the display unit
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	no
Data content	0: Setpoint or differential value (depending on mode, see chapter 4.1.1: Position-bound operating modes) 1: Off

5.7.2.34 5F0Ch: Control word

The control word can be read via object 5F0Ch. Write access is only via RPDO1 or RPDO2 (see chapter 5.3.2: Control word).

Sub-index	00h
Description	Control word
Access	ro
PDO mapping	yes
Data type	UNSIGNED 16
Default	0h
EEPROM	no

5.7.2.35 5F0Dh: Differential value and difference formation

The differential value can be read via object 5F0Dh sub-index 1. The differential value is set by sub-index 2.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	2h
EEPROM	no

Sub-index	01h
Description	differential value
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0h
EEPROM	no

Sub-index	02h
Description	Formation of the differential value
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0: DIFF = ACT – SET 1: DIFF = SET - ACT

5.7.2.36 5F10h: Target window1 (near field)

Object 5F10h indicates the window within which the setpoint is considered reached (see chapter 4.1.1.1: Positioning).

Sub-index	00h
Description	The setpoint is reached when the actual value is within the target window.
Access	rw
PDO mapping	no
Data type	UNSIGNED 16
Default	5h
EEPROM	yes
Data content	0 … 9999

5.7.2.37 5F11h: Decimal places

The object 5F11h indicates the number of decimal places.

Sub-index	00h
Description	number of decimal places
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0 ... 4

5.7.2.38 5F12h: Display orientation and LEDs

Settings of the display orientation and the LEDs can be made via object 5F12h. Furthermore the function of the display backlighting can be set (see chapter 3.3: LED display).

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	9h
EEPROM	no

Sub-index	01h
Description	Display orientation
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0 = 0° 1 = 180° rotated

Sub-index	02h
Description	LED1 green left
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	1h
EEPROM	yes
Data content	0: Off 1: position-dependent

Sub-index	03h
Description	LED2 red left
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	1h
EEPROM	yes
Data content	0: Off 1: position-dependent

Sub-index	04h
Description	LED3 green right
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	1h
EEPROM	yes
Data content	0: Off 1: position-dependent

Sub-index	05h
Description	LED4 red right
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	1h
EEPROM	yes
Data content	0: Off 1: position-dependent

Sub-index	06h
Description	FLASH LED
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0: Off 1: On

Sub-index	07h
Description	white backlight
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	1h
EEPROM	yes
Data content	0: Off 1: On

Sub-index	08h
Description	red backlight
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	1h
EEPROM	yes
Data content	0: Off 1: On

Sub-index	09h
Description	FLASH backlight
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0: Off 1: On

5.7.2.39 5F13h: Display divisor (ADI) and ADI application

The display divisor and its application can be changed via object 5F13h.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	2h
EEPROM	no

Sub-index	01h
Description	display divisor ADI
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0: 1 1: 10 2: 100 3: 1000

Sub-index	02h
Description	ADI application
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	2h
EEPROM	yes
Data content	0: on all values 1: only on the display. Values transferred via the interface are not offset against the ADI values.

5.7.2.40 5F14h: Loop length

Object 5F14h specifies the loop length by which the setpoint shall be moved over with loop travel (see chapter 4.1.1.2: Loop positioning).

Sub-index	00h
Description	loop length
Access	rw
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	yes
Data content	0 ... 9999

5.7.2.41 5F15h: Positioning type

The positioning type, loop type is indicated via object 5F15h, thereby selecting the direction from which the setpoint shall be approached (see chapter 4.1.1.2: Loop positioning).

Sub-index	00h
Description	Setpoint is approached in this direction.
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0: no loop 1: loop + 2: loop -

5.7.2.42 5F16h: Read target value

The current setpoints can be read via object 5F16h.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	4h
EEPROM	no

Sub-index	01h
Description	Set point2 (4 LSB Bytes)
Access	ro
PDO mapping	yes
Data type	UNSIGNED 32
Default	0h
EEPROM	no

Sub-index	02h
Description	Set point2 (2 MSB Bytes)
Access	ro
PDO mapping	yes
Data type	UNSIGNED 32
Default	0h
EEPROM	no

Sub-index	03h
Description	Set point1 (4 LSB Bytes)
Access	ro
PDO mapping	yes
Data type	UNSIGNED 32
Default	0h
EEPROM	no

Sub-index	04h
Description	Set point1 (2 MSB Bytes)
Access	ro
PDO mapping	yes
Data type	UNSIGNED 32
Default	0h
EEPROM	no

5.7.2.43 5F17h: Period counter, sensor ADC values and absolute fine value

The current values of the period counter, the ADC values and the absolute fine value can be queried via object 5F17h.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	3h
EEPROM	no

Sub-index	01h			
Description	values of the period counter			
Access	ro			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	0h			
EEPROM	no			
Data content	Byte 0	Byte 1	Byte 2	Byte 3
	Quadrant	Period counter		

Sub-index	02h			
Description	sensor ADC values			
Access	ro			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	0h			
EEPROM	no			
Data content	Byte 0	Byte 1	Byte 2	Byte 3
	ADC_SIN		ADC_COS	

Sub-index	03h
Description	absolute fine value
Access	ro
PDO mapping	no
Data type	SIGNED 16
Default	0h
EEPROM	no

5.7.2.44 5F19h: Status word

Object 5F19h informs about the current device status (see chapter 5.3.3: Status word).

Sub-index	00h
Description	The status word informs about the current device status.
Access	ro
PDO mapping	yes
Data type	UNSIGNED 16
Default	0h
EEPROM	no

5.7.2.45 5F1Bh: Sensor type and operating mode

The sensor type can be read and the operating mode changed via object 5F1Bh.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	2h
EEPROM	no

Sub-index	01h
Description	sensor type
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h (MS500H)
EEPROM	yes
Data content	0: MS500H 1: GS04

Sub-index	02h
Description	operating mode
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	no
Data content	0: Absolute position 1: Difference 2: Modulo (360° angle display) 3: Alpha-numeric display

5.7.2.46 5F1Ch: Acknowledgement settings

Object 5F1Ch serves for determining the key to be used as acknowledgement key. The setting is only relevant in the alpha-numeric display mode.

Sub-index	00h
Description	acknowledgement settings
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0: ✳ key 2: Up and Left key

5.7.2.47 5F1Fh: Direction indicators (CW, CCW)

The display of the direction arrows is set via object 5F1Fh.

Sub-index	00h
Description	direction indicators (CW,CCW)
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0: On 1: inverted 2: Off

5.7.2.48 5F21h: Target window2 (far) and target window2 visualization

Via object 5F21h, the size of target window2 can be set and visualization of target window2 enabled and disabled (see chapter 4.1.1.1: Positioning).

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	2h
EEPROM	no

Sub-index	01h
Description	Target window2
Access	rw
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	yes
Data content	0 ... 9999

Sub-index	02h
Description	Target window2 visualization
Access	rw
PDO mapping	no
Data type	UNSIGNED 8
Default	0h
EEPROM	yes
Data content	0: Off 1: On

5.7.2.49 6000h: Operating Parameters

Settings of the operating parameters can be made by object 6000h.

Sub-index	00h	
Description	Operating Parameters	
Access	rw	
PDO mapping	no	
Data type	UNSIGNED 16	
Default	4h	
EEPROM	yes	
Data content	Bit 15 ... 4	not used
	Bit 3	MS500H: 0: positive counting direction 1: negative counting direction
	Bit 2	1: Scaling enabled
	Bit 1	not used
	Bit 0	GS04: 0: clockwise sense of rotation I (CW) 1: counter-clockwise sense of rotation E (CCW)

Scaling: The encoder functions with its set APU (Display per revolution or Measuring units per revolution), which can be configured via object 6001h. The scaling function cannot be disabled.

MS500H:

Positive counting direction: ascending position values when sensor moves to the sensor cable.

Negative counting direction: ascending position values when sensor moves away from the sensor cable.

GS04:

I sense of rotation: ascending position values with clockwise shaft rotation (CW, view on the display).

E sense of rotation: ascending position values with counter-clockwise shaft rotation (CCW, view on the display).

5.7.2.50 6001h: Measuring steps per revolution (Display per revolution = APU)

Object 6001h determines the number of measuring steps per revolution.

Sub-index	00h
Description	number of measuring steps per revolution
Access	rw
PDO mapping	no
Data type	UNSIGNED 32
Default	720 (GS04)
EEPROM	yes
Data content	1 ... 65535

5.7.2.51 6002h: Total of measuring steps

6002h indicates the total of measuring steps of the system.

Sub-index	00h
Description	total of measuring steps
Access	rw
PDO mapping	no
Data type	UNSIGNED 32
Default	6E0036Fh
EEPROM	yes
Data content	1745h ... 1745C5C1h

5.7.2.52 6003h: Preset value (calibration value)

Via object 6003h, the encoder's position value can be set to a calibration value when calibrating. Position value = measured value + calibration value + offset value.

Sub-index	00h
Description	Calibration value
Access	rw
PDO mapping	no
Data type	SIGNED 32
Default	0h
EEPROM	yes
Data content	-999999 ... 999999

5.7.2.53 6004h: Position value

Object 6004h indicates the current position value of the device.

Sub-index	00h
Description	Position value
Access	ro
PDO mapping	yes
Data type	SIGNED 32
Default	0h
EEPROM	no

Position value = measured value + calibration value + offset value

5.7.2.54 6005h: Resolution

Via object 6005h, resolution is determined when the MS500H linear sensor is used.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	1h
EEPROM	no

Sub-index	01h
Description	Resolution for linear sensor. According to DS406 the parameter must be indicated in multiples of nm.
Access	rw
PDO mapping	no
Data type	UNSIGNED 32
Default	10000
EEPROM	yes
Data content	310 ... 2114064575

5.7.2.55 6200h: Cycle Timer

Object 6200h sets a cycle time for the output of PDO1. This value is permanently linked to the object 1800h: 1. Transmit PDO Parameter sub-index 5. Timer-controlled output is active as soon as a valid cycle time has been entered and the device run in the Operational Mode. The value 0 deactivates the function.

Sub-index	00h
Description	Zyklus Timer
Access	rw
PDO mapping	no
Data type	UNSIGNED 16
Default	0h
EEPROM	yes
Data content	0 ... 65535

5.7.2.56 6500h: Operating Status

Object 6500h indicates the settings programmed with object 6000h.

Sub-index	00h	
Description	Operating Status	
Access	ro	
PDO mapping	no	
Data type	UNSIGNED 16	
Default	4h	
EEPROM	no	
Data content	Bit 15 ... 4	not used
	Bit 3	MS500H: 0: positive counting direction 1: negative counting direction
	Bit 2	1: Scaling enabled
	Bit 1	not used
	Bit 0	GS04: 0: Clockwise sense of rotation I (CW) 1: Counter-clockwise sense of rotation E (CCW)

5.7.2.57 6501h: Single-turn resolution

Object 6501h indicates the physical number of measuring steps per revolution.

Sub-index	00h
Description	physical resolution
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	MS500H: 10000 GS04: 720
EEPROM	no

5.7.2.58 6502h: Number of distinguishable revolutions

Object 6502h indicates the number of revolutions the encoder is able to distinguish.

Sub-index	00h
Description	total of distinguishable revolutions
Access	ro
PDO mapping	no
Data type	UNSIGNED 16
Default	MS500H: 1 GS04: 7281
EEPROM	no

5.7.2.59 6503h: Alarms

Object 6503h sends device-specific alarm messages in addition to the errors reported via the Emergency message. In the case of an error, the associated bit is set to 1.

Sub-index	00h	
Description	alarm messages	
Access	ro	
PDO mapping	no	
Data type	UNSIGNED 16	
Default	0h	
EEPROM	no	
Data content	Bit 15 ... 14	not used
	Bit 13	0: battery not discharged 1: battery discharged
	Bit 12	0: battery voltage OK 1: battery voltage critical
	Bit 11 ... 1	not used
	Bit 0	0: position value valid 1: position value invalid

5.7.2.60 6504h: Supported Alarms

This object 6504h indicates the alarm messages that are supported. The relevant bits are set.

Sub-index	00h	
Description	supported alarm messages	
Access	ro	
PDO mapping	no	
Data type	UNSIGNED 16	
Default	3001h	
EEPROM	no	
Data content	Bit 15 ... 14	not used
	Bit 13	battery emty
	Bit 12	battery critical
	Bit 11 ... 1	not used
	Bit 0	position error

5.7.2.61 6505h: Warnings

The warning messages displayed via object 6505h indicate that tolerances of internal encoder parameters have been exceeded. However, unlike with alarm messages, the position value can be valid in case of a warning.

Sub-index	00h	
Description	warnings	
Access	ro	
PDO mapping	no	
Data type	UNSIGNED 16	
Default	0h	
EEPROM	no	
Data content	Bit 15 ... 5	not used
	Bit 4	0: battery voltage OK 1: battery voltage critical
	Bit 3 ... 0	not used

5.7.2.62 6506h: Supported Warnings

Object 6506h indicates the warning messages that are supported.

Sub-index	00h	
Description	supported Warnings	
Access	ro	
PDO mapping	no	
Data type	UNSIGNED 16	
Default	0010h	
EEPROM	no	
Data content	Bit 15 ... 5	not used
	Bit 4	battery warning
	Bit 3 ... 0	not used

5.7.2.63 6507h: Profile and Software Version

The object 6507h indicates the encoder profile used (CANopen Device profile for encoders) and the version number of the firmware state

Sub-index	00h			
Description	Profile and software version			
Access	ro			
PDO mapping	no			
Data type	UNSIGNED 32			
Default	01000302h			
EEPROM	no			
	Profile version		Software version	
	Byte 0 (LSB)	Byte 1	Byte 2	Byte 3 (MSB)
	02	03	00	01

5.7.2.64 6508h: Operating Time

The operating hours are displayed via object 6508h. This function is not supported.

Sub-index	00h
Description	operating hours counter
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	0xFFFFFFFFh
EEPROM	no

5.7.2.65 6509h: Encoder calibration value

Via object 6509h, the difference between the encoder value and the scaled position value offset against Preset and Manufacturer Offset is output.

Sub-index	00h
Description	encoder status at the time of calibration
Access	ro
PDO mapping	no
Data type	SIGNED 32
Default	0h
EEPROM	yes

5.7.2.66 650Ah: Module Identification

Object 650Ah indicates the manufacturer-specific offset value as well as the smallest and largest transferable position value.

Sub-index	00h
Description	indicates the largest sub-index supported
Access	ro
PDO mapping	no
Data type	UNSIGNED 8
Default	3h
EEPROM	no

Sub-index	01h
Description	Manufacturer-specific offset value is added to the position value (see object 2001h: Manufacturer Offset).
Access	ro
PDO mapping	no
Data type	SIGNED 32
Default	0h
EEPROM	no

Sub-index	02h
Description	smallest transferable position value
Access	ro
PDO mapping	no
Data type	SIGNED 32
Default	MS500H: -65536000 GS04: -5242880
EEPROM	no

Sub-index	03h
Description	largest transferable position value
Access	ro
PDO mapping	no
Data type	SIGNED 32
Default	MS500H: 65536000 GS04: 5242880
EEPROM	no

5.7.2.67 650Bh: Serial Number

Object 650Bh outputs the serial number of the encoder. This function is not supported.

Sub-index	00h
Description	Serial number
Access	ro
PDO mapping	no
Data type	UNSIGNED 32
Default	FFFFFFFFh
EEPROM	no